IN THE SPECIFICATION:

Please replace paragraph [0002] with the following amended paragraph:

[0002] Tripode joints of the above-mentioned type have been produced and distributed by ~~the applicant~~ GKN Driveline Deutschland GmbH for some time under the designation of AAR tripode joints. In particular, they are used in motor vehicle driveshafts such as sideshafts which serve to provide a driving connection between the differential drive and the driving wheels. It is common practice to use so-called constant velocity fixed ball joints at the wheel end and so-called AAR tripode joints as plunging joints at the differential. To date, the AAR tripode joints have been designed for articulation angles ranging from approximately 23° to 26°. In connection with the increasing popularity of off-road vehicles and sport utility vehicles, there is an increasing demand for larger operational articulation angles which, so far, has meant that the so-called AAR tripode joints were replaced by double offset joints which are also axially displaceable (DO plunging joints) or by a combination of constant velocity fixed ball joints and axial plunging units. Such solutions are either less advantageous in respect of their NVH (noise, vibration, harshness) behavior (DO plunging joints) or generate much higher production costs (fixed ball joints with additional plunging units). Thus, there exits a need for tripode joint having an increased articulation angle.

Please replace paragraph [0015] with the following amended paragraph:

[0015] ~~Figure 5 shows~~ Figure 5A and 5B show a tripode joint with a roller embodiment according to Figure 4 in a cross-section at an articulation angle of 17°, and in ~~with~~ an enlarged detail, respectively.

Please replace paragraph [0016] with the following amended paragraph:

[0016] ~~Figure 6 shows~~ Figures 6A and 6B show a tripode joint with a roller embodiment according to Figure 4 in a cross-section at an articulation angle of 31°, and in ~~with~~ an enlarged detail, respectively.

Please replace paragraph [0020] with the following amended paragraph:

[0020] Figure 3 shows an inventive roller assembly in half a section through the roller axis in a first embodiment. The associated tripode arm can also be seen. The Figure shows the relative position which is assumed when the joint is in the aligned position, with the axes A11 and A12 coinciding. WZ refers to the effective line by which the spherical face 22 of the arm head 21 acts on the roller carriers 23 of the roller assembly. WR refers to the effective line by which the track 16 in the outer joint part acts on the roller 25. The parallel offset of the two effective lines shows that, when torque is transmitted, a tilting moment is applied to the roller assembly, so that, when the joint is in an aligned position, the roller assembly assumes a stable position of contact within the tracks. The bearing needles 24 as well as the roller carriers 23 are held by two securing rings 26, 27 relative to the roller 25 in such a way that they cannot get lost. The two securing rings engage inner grooves 36, 37 formed in the cylindrical inner face of the roller 25. On its outside, the roller carrier 23 is held by two stop collars 38, 39 with an axial displacement clearance between the securing rings 26, 27 and, with reference to the axis (not shown) of the tripode star, on the radial inside end, comprises a cylindrical projection 42. <u>The stop collars 38, 39 delimit the axial length of the needle contact face 41.</u> The axial length of the needle contact face 41 positioned on the outside is smaller by the displacement clearance SA than the inner distance between the securing rings 26, 27. The length of the arm contact face 40 on the inside corresponds to the inner distance between the securing rings 26, 27. The axial displacement clearance SA is obtained as a result of the shortened needle contact face 41 on the outside of the roller carrier 23 relative to the arm contact face 40 on the inside of the roller carrier 23. <u>Thus, the cylindrical projections 42, with respect to the roller axes AR, increase the axial length of the arm contact face 40 beyond the extension of the needle contact face 41. However, in this example, at the radial outside end of each roller carrier, with respect to the first longitudinal axis A11, the arm contact face 40 and the needle contact face 41 are flush with each other.</u> ~~As far as the functioning of the inventive joint is concerned, the roller carrier 23 should be radially inwardly displaceable relative to the roller 25 with reference to the axis of the tripode star, which displaceability permits greater movement of the arm head 21 when the joint is articulated in that the arm head 21 takes along the roller carrier 23 radially inwardly via friction forces and, in the process, displaces the arm contact face 40 far enough for the contact with the arm head 21 not to be lost. The greater arm head movements which are possible as a result correspond to greater articulation movements of the joint.~~

Please add the following new paragraphs after paragraph [0020]:

[0020.1] As far as the functioning of the inventive joint is concerned, the roller carrier 23 should be radially inwardly displaceable relative to the roller 25 with reference to the axis of the tripode star, which displaceability permits greater movement of the arm head 21 when the joint is articulated in that the arm head 21 takes along the roller carrier 23 radially inwardly via friction forces and, in the process, displaces the arm contact face 40 far enough for the contact with the arm head 21 not to be lost. The greater arm head movements which are possible as a result correspond to greater articulation movements of the joint.

Please replace paragraph [0021] with the following amended paragraph:

[0021] Figure 4 shows an inventive roller assembly as already illustrated in Figure 3, in a half-section through the roller axis in a modified embodiment. The associated tripode arm 19 can again be seen, with the Figure showing the relative position assumed when the joint is in the aligned condition, with the axes 11 and 12 coinciding. WR refers to the effective line by which the track 16 in the outer joint part acts on the roller 25. The parallel offset of the two effective lines shows that, when torque is transmitted, a tilting moment is applied to the roller assembly, so that, when the joint is in an aligned position, the roller assembly assumes a stable position of contact within the tracks. The bearing needles 24 as well as the roller carriers ~~23~~ 123 are held by two securing rings 26, 27 relative to the roller 25 in such a way that they cannot get lost. The two securing rings engage inner grooves 36, 37 formed in the cylindrical inner face of the roller 25. On its outside, the roller carrier ~~23~~ 123 is held by two stop collars 38, ~~39~~ 139 with an axial displacement clearance between the securing rings 26, 27 and, with reference to the axis (not shown) of the tripode star, on the radial inside end, comprises a cylindrical projection 42 and, on the radial outside end, a cylindrical projection 43. The stop collars 38, 139 delimit the axial length of the needle contact face 41. The axial length of the needle contact face 41 positioned on the outside is smaller by the displacement clearance SA than the inner distance between the securing rings 26, 27. The length of the arm contact face 40 on the inside corresponds to the inner distance between the securing rings 26, 27. The axial displacement clearance SA is obtained as a result of the needle contact face 41, on the outside of the roller carrier ~~23~~ 123, being shortened by an amount SA/2 on both sides, relative to the arm contact face 40 on the inside of the roller carrier ~~23~~ 123. Thus, the cylindrical projections 42, 43, with respect to the roller axes AR, increase the axial length of the arm contact face 40 beyond the extension of the needle contact face 41 on both the radial inside end and the radial outside end. ~~As far as the functioning of the inventive joint is concerned, the roller carrier 23 should be radially inwardly displaceable relative to the roller 25 with reference to the axis of the tripode star, which displaceability permits greater movements of the arm head 21 when the joint is articulated. Otherwise,~~

~~the functioning process substantially corresponds to that of the roller assembly according to Figure 3.~~

Please add the following new paragraphs after paragraph [0021]:

[0021.1] As far as the functioning of the inventive joint is concerned, the roller carrier 123 should be radially inwardly displaceable relative to the roller 25 with reference to the axis of the tripode star, which displaceability permits greater movements of the arm head 21 when the joint is articulated. Otherwise, the functioning process substantially corresponds to that of the roller assembly according to Figure 3.

Please replace paragraph [0022] with the following amended paragraph:

[0022] ~~Figure 5 shows~~ Figures 5A and 5B show the joint according to Figure ~~1~~ 4 in an illustration analogous to that of Figure 1 in a cross-sectional view, but, relative to the axis A11 of the outer joint part 11, which axis is positioned normally on the drawing plane. The axis A12 of the tripode star 12 is articulated downwardly by 17°. As a result, the upwardly pointing tripode arm 19 has moved forwards from a central sectional position relative to the drawing plane, and the two tripode arms pointing downwardly at an angle have moved backwards from a central sectional position relative to the drawing plane. As a result of this articulation movement, the centers (not illustrated) of the spherical faces 22 of the arm heads 21 and thus also the contact points of the arm heads 21 have each moved radially inwards in the sectional plane relative to the roller carriers ~~23~~ 123. The consequences thereof can be seen in the enlarged detail. The effective line WZ of the arm heads acting on the roller carrier is now clearly radially positioned inside the unchanged effective line WR of the outer joint part relative to the roller 25 which is positioned in the symmetry plane of the roller 25. In this illustration, the roller carrier ~~23~~ 123 is shown in continuous lines in the radially outermost position relative to the roller 25 and the bearing needles 24, a position which the roller carrier ~~23~~ 123 assumes when, free from torque, it moves radially outwardly under the influence of a centrifugal force. When the arm head 21, under torque load, moves from the outermost position radially inwardly, the roller carrier ~~23~~ 123 will leave its outermost position and will move towards the extreme position on the radial inside, which extreme position is shown in dashed lines. The actual position of the roller carrier when torque-loaded should be between the two illustrated positions.

Please replace paragraph [0023] with the following amended paragraph:

[0023] ~~Figure 6 shows~~ Figures 6A and 6B show the joint according to ~~Figure 5~~ Figures 5A and 5B in an illustration which is analogous to the shown in ~~Figure 5~~ Figures 5A and 5B, in a cross-sectional view but, relative to the axis A11 of the outer joint part which is positioned normally on the drawing plane, the axis A12 of the tripode star is articulated perpendicularly downwardly by 31°. As a result, the upwardly pointing tripode arm 19 has moved further forwards relative to the drawing plane, and the two tripode arms pointing downwardly at an angle have again moved further backwards relative to the drawing plane. As a result of this articulation movement, the centers of the spherical faces 22 of the arm heads 21 and thus also the contact points of the arm heads 21 have each moved further radially inwards in the sectional plane relative to the roller carriers ~~23~~ 123. The consequences thereof can be seen in the enlarged detail. The effective line WZ of the arm heads acting on the roller carrier is now positioned at a greater distance radially inside the unchanged effective line WR of the outer joint part relative to the roller which is positioned in the symmetry plane of the roller 25. In this illustration, the roller carrier ~~23~~ 123 is shown in continuous lines in the radially inner extreme position relative to the roller 25 and the bearing needles 24, a position which the roller carrier ~~23~~ 123 assumes when, via the friction forces of the spherical face 22 which act on the arm contact face 40, it is pushed radially inwardly when the joint moves from an aligned position with coaxial axes A11, A12 into the maximum articulated position. As a result, the spherical face 22 of the arm head 21 continues to have secure contact with the arm contact face 40 of the roller carrier ~~23~~ 123. In the examples of Figures 5A, 5B, 6A and 6B, it can be seen that, at the roller assemblies, the axial length of the cylindrical projection 42 and the amount of axial displacement clearance SA are dimensioned such that, with a joint articulation angle of at least 27°, and more particularly of at least 31°, the spherical surface portions 22 of the arm heads 21 are able to establish a carrying contact with the arm contact faces 40 of the roller carriers. The displacement clearance SA can amount to at least 5% of the carrying length of the bearing needles, preferably at least 10% of the length and, in some cases, it can amount to 20-25% of the carrying length of the bearing needles.